

In the Claims:

Please amend the claims as follows:

1 (cancelled)

2. (currently amended) The industrial robot according to claim ~~4~~, 10, wherein the second supporting arm comprises a bearing and is adapted to rotate in a plane intersecting the movable platform.

3. (cancelled)

4. (currently amended) The industrial robot according to claim ~~4~~, 10, wherein the third linkage comprises a triangle ~~where the~~ having a base that is journaled in the movable platform.

5. (currently amended) The industrial robot according to claim ~~4~~, 10, wherein the third linkage comprises a locked double link.

6 (cancelled)

7. (withdrawn) A method for manufacturing an industrial robot, with which an object is moved in space, comprising providing the industrial robot with a stationary platform, a movable platform adapted for supporting the object, and a first, a second and a third arm to which the

platforms are joined, wherein the first arm is brought to comprise a first actuator, a first supporting arm influenced by the first actuator and rotatable around a first axis, and a first linkage, the second arm is brought to comprise a second actuator, a second supporting arm influenced by the second actuator and rotatable around a second axis, and a second linkage, and the third arm is brought to comprise a third actuator, a third supporting arm influenced by the third actuator and rotatable around a third axis, and a third linkage, wherein the first and third axes are arranged parallel and that the second supporting arm is arranged freely journaled around a transverse axis that is substantially arranged at right angles to the second axis.

8. (withdrawn) Use of an industrial robot according to claim 1 during laser cutting.

9. (withdrawn) Use of a method according to claim 7 during laser cutting.

10. (new) An industrial robot for moving an object in space, the industrial robot comprising:

- a stationary platform;

- a movable platform adapted for supporting the object;

- a first arm comprising a first supporting arm operatively connected to the stationary platform, a first actuator configured to rotate the first supporting arm about a first axis, and a first linkage operatively connected between the first supporting arm and the movable platform, wherein the first linkage comprises a triangle having a base that is journaled in the moveable platform;

- a second arm comprising a second supporting arm operatively connected to the stationary

platform, a second actuator configured to rotate the second supporting arm about a second axis, and a second linkage operatively connected between the second supporting arm and the movable platform, wherein the second linkage comprises a triangle having a base that is journaled in the moveable platform; and

a third arm comprising a third supporting arm operatively connected to the stationary platform, a third actuator configured to rotate the third supporting arm about a third axis, and a third linkage operatively connected between the third supporting arm and the movable platform,

wherein the first axis and the second axis are parallel, and wherein the third supporting arm is journaled around a transverse axis that is arranged in a plane substantially normal to the second axis.

11. (new) An industrial robot for moving an object in space, the industrial robot comprising:

a stationary platform;

a movable platform adapted for supporting the object;

a first arm comprising a first supporting arm operatively connected to the stationary platform, a first actuator configured to displace the first supporting arm along a first path, and a first linkage operatively connected between the first supporting arm and the movable platform, wherein the first linkage comprises a triangle having a base that is journaled in the moveable platform;

a second arm comprising a second supporting arm operatively connected to the stationary platform, a second actuator configured to displace the second supporting arm along a second path, and a second linkage operatively connected between the second supporting arm and the

movable platform, wherein the second linkage comprises a triangle having a base that is journaled in the moveable platform; and

a third arm comprising a first supporting arm operatively connected to the stationary platform, a third actuator configured to displace the third supporting arm along a third path, and a third linkage operatively connected between the third supporting arm and the movable platform,

wherein the first path and the second path are parallel, and wherein the third supporting arm is journaled around a transverse axis that is arranged at substantially a right angle to the second path.